

Ken Goldberg

List of Publications by Year in descending order

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Version: 2024-02-01

209
papers

9,802
citations

136950

32
h-index

76900

74
g-index

214
all docs

214
docs citations

214
times ranked

6843
citing authors

#	ARTICLE	IF	CITATIONS
1	Automating Surgical Peg Transfer: Calibration With Deep Learning Can Exceed Speed, Accuracy, and Consistency of Humans. IEEE Transactions on Automation Science and Engineering, 2023, 20, 909-922.	5.2	7
2	VisuoSpatial Foresight for physical sequential fabric manipulation. Autonomous Robots, 2022, 46, 175-199.	4.8	15
3	Comparison of novel shielded nasopharynx applicator designs for intracavitary brachytherapy. Brachytherapy, 2022, 21, 229-237.	0.5	1
4	Simulating Polyculture Farming to Learn Automation Policies for Plant Diversity and Precision Irrigation. IEEE Transactions on Automation Science and Engineering, 2022, 19, 1352-1364.	5.2	6
5	REACH: Reducing False Negatives in Robot Grasp Planning with Robust Efficient Area Contact Hypothesis Model. Springer Proceedings in Advanced Robotics, 2022, , 757-772.	1.3	2
6	Deep Transfer Learning of Pick Points on Fabric for Robot Bed-Making. Springer Proceedings in Advanced Robotics, 2022, , 275-290.	1.3	18
7	Mitigating Network Latency in Cloud-Based Teleoperation Using Motion Segmentation and Synthesis. Springer Proceedings in Advanced Robotics, 2022, , 906-921.	1.3	5
8	Real2Sim2Real: Self-Supervised Learning of Physical Single-Step Dynamic Actions for Planar Robot Casting. , 2022, , .		12
9	Mechanical Search on Shelves using a Novel "Bluction" Tool. , 2022, , .		7
10	LEGS: Learning Efficient Grasp Sets for Exploratory Grasping. , 2022, , .		1
11	GOMP-FIT: Grasp-Optimized Motion Planning for Fast Inertial Transport. , 2022, , .		8
12	Learning to Localize, Grasp, and Hand Over Unmodified Surgical Needles. , 2022, , .		11
13	IPC-GraspSim: Reducing the Sim2Real Gap for Parallel-Jaw Grasping with the Incremental Potential Contact Model. , 2022, , .		3
14	ABC-LMPC: Safe Sample-Based Learning MPC for Stochastic Nonlinear Dynamical Systems with Adjustable Boundary Conditions. Springer Proceedings in Advanced Robotics, 2021, , 1-17.	1.3	2
15	Partial caging: a clearance-based definition, datasets, and deep learning. Autonomous Robots, 2021, 45, 647-664.	4.8	2
16	Getting a grip on reality. Science Robotics, 2021, 6, .	17.6	1
17	Recovery RL: Safe Reinforcement Learning With Learned Recovery Zones. IEEE Robotics and Automation Letters, 2021, 6, 4915-4922.	5.1	66
18	Serverless Multi-Query Motion Planning for Fog Robotics. , 2021, , .		4

#	ARTICLE	IF	CITATIONS
19	Learning Seed Placements and Automation Policies for Polyculture Farming with Companion Plants. , 2021, , .		6
20	Learning to Rearrange Deformable Cables, Fabrics, and Bags with Goal-Conditioned Transporter Networks. , 2021, , .		56
21	Intermittent Visual Servoing: Efficiently Learning Policies Robust to Instrument Changes for High-precision Surgical Manipulation. , 2021, , .		14
22	Robots of the Lost Arc: Self-Supervised Learning to Dynamically Manipulate Fixed-Endpoint Cables. , 2021, , .		13
23	Learning Dense Visual Correspondences in Simulation to Smooth and Fold Real Fabrics. , 2021, , .		22
24	Disentangling Dense Multi-Cable Knots. , 2021, , .		6
25	Five years of <i>Science Robotics</i>. Science Robotics, 2021, 6, eabn2720.	17.6	2
26	GOMP: Grasp-Optimized Motion Planning for Bin Picking. , 2020, , .		19
27	Deep learning can accelerate grasp-optimized motion planning. Science Robotics, 2020, 5, .	17.6	27
28	Non-Markov Policies to Reduce Sequential Failures in Robot Bin Picking. , 2020, , .		3
29	Efficiently Calibrating Cable-Driven Surgical Robots With RGBD Fiducial Sensing and Recurrent Neural Networks. IEEE Robotics and Automation Letters, 2020, 5, 5937-5944.	5.1	24
30	Industrial Robot Grasping with Deep Learning using a Programmable Logic Controller (PLC). , 2020, , .		17
31	Simulating Polyculture Farming to Tune Automation Policies for Plant Diversity and Precision Irrigation. , 2020, , .		6
32	Multirobot Routing Algorithms for Robots Operating in Vineyards. IEEE Transactions on Automation Science and Engineering, 2020, , 1-11.	5.2	19
33	RLaaS: Robot Inference and Learning as a Service. IEEE Robotics and Automation Letters, 2020, 5, 4423-4430.	5.1	17
34	Combating COVID-19â€™The role of robotics in managing public health and infectious diseases. Science Robotics, 2020, 5, .	17.6	393
35	Safety Augmented Value Estimation From Demonstrations (SAVED): Safe Deep Model-Based RL for Sparse Cost Robotic Tasks. IEEE Robotics and Automation Letters, 2020, 5, 3612-3619.	5.1	33
36	Deep Imitation Learning of Sequential Fabric Smoothing From an Algorithmic Supervisor. , 2020, , .		39

#	ARTICLE	IF	CITATIONS
37	SWIRL: A Sequential Windowed Inverse Reinforcement Learning Algorithm for Robot Tasks With Delayed Rewards. Springer Proceedings in Advanced Robotics, 2020, , 672-687.	1.3	1
38	Synthesis of Energy-Bounded Planar Caging Grasps using Persistent Homology. Springer Proceedings in Advanced Robotics, 2020, , 416-431.	1.3	0
39	X-Ray: Mechanical Search for an Occluded Object by Minimizing Support of Learned Occupancy Distributions. , 2020, , .		19
40	Applying Depth-Sensing to Automated Surgical Manipulation with a da Vinci Robot. , 2020, , .		20
41	SWIRL: A sequential windowed inverse reinforcement learning algorithm for robot tasks with delayed rewards. International Journal of Robotics Research, 2019, 38, 126-145.	8.5	35
42	A Fog Robotic System for Dynamic Visual Servoing. , 2019, , .		25
43	Segmenting Unknown 3D Objects from Real Depth Images using Mask R-CNN Trained on Synthetic Data. , 2019, , .		112
44	Robust 2D Assembly Sequencing via Geometric Planning with Learned Scores. , 2019, , .		5
45	Applying machine learning to predict future adherence to physical activity programs. BMC Medical Informatics and Decision Making, 2019, 19, 169.	3.0	32
46	On-Policy Dataset Synthesis for Learning Robot Grasping Policies Using Fully Convolutional Deep Networks. IEEE Robotics and Automation Letters, 2019, 4, 1357-1364.	5.1	81
47	Adversarial Grasp Objects. , 2019, , .		14
48	Partial Caging: A Clearance-Based Definition and Deep Learning. , 2019, , .		4
49	RAPID-MOLT: A Meso-scale, Open-source, Low-cost Testbed for Robot Assisted Precision Irrigation and Delivery. , 2019, , .		3
50	Automated Extraction of Surgical Needles from Tissue Phantoms. , 2019, , .		13
51	Dex-Net MM: Deep Grasping for Surface Decluttering with a Low-Precision Mobile Manipulator. , 2019, , .		4
52	Multi-Task Hierarchical Imitation Learning for Home Automation. , 2019, , .		10
53	Robust Toppling for Vacuum Suction Grasping. , 2019, , .		3
54	Learning ambidextrous robot grasping policies. Science Robotics, 2019, 4, .	17.6	321

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55	Robots and the return to collaborative intelligence. <i>Nature Machine Intelligence</i> , 2019, 1, 2-4.	16.0	47
56	Transition State Clustering: Unsupervised Surgical Trajectory Segmentation for Robot Learning. <i>Springer Proceedings in Advanced Robotics</i> , 2018, , 91-110.	1.3	20
57	Malasakit 2.0: A Participatory Online Platform with Feature Phone Integration and Voice Recognition for Crowdsourcing Disaster Risk Reduction Strategies in the Philippines. , 2018, , .		1
58	Dex-Net as a Service (DNaaS): A Cloud-Based Robust Robot Grasp Planning System. , 2018, , .		10
59	A Cloud-Based Robust Semaphore Mirroring System for Social Robots. , 2018, , .		5
60	Linear Push Policies to Increase Grasp Access for Robot Bin Picking. , 2018, , .		37
61	Towards Automating Precision Irrigation: Deep Learning to Infer Local Soil Moisture Conditions from Synthetic Aerial Agricultural Images. , 2018, , .		21
62	Dex-Net 3.0: Computing Robust Vacuum Suction Grasp Targets in Point Clouds Using a New Analytic Model and Deep Learning. , 2018, , .		158
63	Deep Imitation Learning for Complex Manipulation Tasks from Virtual Reality Teleoperation. , 2018, , .		263
64	Fast and Reliable Autonomous Surgical Debridement with Cable-Driven Robots Using a Two-Phase Calibration Procedure. , 2018, , .		38
65	Guest Editorial Open Discussion of Robot Grasping Benchmarks, Protocols, and Metrics. <i>IEEE Transactions on Automation Science and Engineering</i> , 2018, 15, 1440-1442.	5.2	19
66	Synthesis of Energy-Bounded Planar Caging Grasps Using Persistent Homology. <i>IEEE Transactions on Automation Science and Engineering</i> , 2018, 15, 908-918.	5.2	9
67	Evaluating Machine Learning-Based Automated Personalized Daily Step Goals Delivered Through a Mobile Phone App: Randomized Controlled Trial. <i>JMIR MHealth and UHealth</i> , 2018, 6, e28.	3.7	69
68	Objectively Measured Baseline Physical Activity Patterns in Women in the mPED Trial: Cluster Analysis. <i>JMIR Public Health and Surveillance</i> , 2018, 4, e10.	2.6	21
69	Design of parallel-jaw gripper tip surfaces for robust grasping. , 2017, , .		33
70	Comparing human-centric and robot-centric sampling for robot deep learning from demonstrations. , 2017, , .		32
71	A cloud robot system using the dexterity network and berkeley robotics and automation as a service (Brass). , 2017, , .		22
72	M-CAFE 2.0. , 2017, , .		0

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73	An algorithm and user study for teaching bilateral manipulation via iterated best response demonstrations. , 2017, , .		2
74	Multilateral surgical pattern cutting in 2D orthotropic gauze with deep reinforcement learning policies for tensioning. , 2017, , .		81
75	Malasakit 1.0: A participatory online platform for crowdsourcing disaster risk reduction strategies in the philippines. , 2017, , .		3
76	Transition state clustering: Unsupervised surgical trajectory segmentation for robot learning. International Journal of Robotics Research, 2017, 36, 1595-1618.	8.5	58
77	Topological trajectory clustering with relative persistent homology. , 2016, , .		14
78	High-dimensional Winding-Augmented Motion Planning with 2D topological task projections and persistent homology. , 2016, , .		10
79	Dex-Net 1.0: A cloud-based network of 3D objects for robust grasp planning using a Multi-Armed Bandit model with correlated rewards. , 2016, , .		220
80	An interchangeable surgical instrument system with application to supervised automation of multilateral tumor resection. , 2016, , .		20
81	Large-scale supervised learning of the grasp robustness of surface patch pairs. , 2016, , .		14
82	Robot grasping in clutter: Using a hierarchy of supervisors for learning from demonstrations. , 2016, , .		41
83	Occlusion-aware multi-robot 3D tracking. , 2016, , .		4
84	Tumor localization using automated palpation with Gaussian Process Adaptive Sampling. , 2016, , .		46
85	ActiveClean. Proceedings of the VLDB Endowment, 2016, 9, 948-959.	3.8	134
86	Networked Robots. Springer Handbooks, 2016, , 1109-1134.	0.6	3
87	Privacy-preserving Grasp Planning in the Cloud. , 2016, , .		7
88	DATE: A handheld co-robotic device for automated tuning of emitters to enable precision irrigation. , 2016, , .		7
89	PrivateClean. , 2016, , .		16
90	ActiveClean. , 2016, , .		43

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91	SHIV: Reducing supervisor burden in DAgger using support vectors for efficient learning from demonstrations in high dimensional state spaces. , 2016, , .		25
92	Energy-Bounded Caging: Formal Definition and 2-D Energy Lower Bound Algorithm Based on Weighted Alpha Shapes. IEEE Robotics and Automation Letters, 2016, 1, 508-515.	5.1	33
93	Editorial Fine-Tuning T-ASE. IEEE Transactions on Automation Science and Engineering, 2016, 13, 3-3.	5.2	3
94	A Case Study in Mobile-Optimized vs. Responsive Web Application Design. , 2015, , .		4
95	Models of human-centered automation in a debridement task. , 2015, , .		7
96	Evaluation of PCâ€šISO for customized, 3D printed, gynecologic HDR brachytherapy applicators. Journal of Applied Clinical Medical Physics, 2015, 16, 246-253.	1.9	55
97	A paced shared-control teleoperated architecture for supervised automation of multilateral surgical tasks. , 2015, , .		17
98	M-CAFE. , 2015, , .		7
99	Active exploration using trajectory optimization for robotic grasping in the presence of occlusions. , 2015, , .		31
100	GP-GPIS-OPT: Grasp planning with shape uncertainty using Gaussian process implicit surfaces and Sequential Convex Programming. , 2015, , .		34
101	Learning by observation for surgical subtasks: Multilateral cutting of 3D viscoelastic and 2D Orthotropic Tissue Phantoms. , 2015, , .		121
102	The Slip-Pad: A haptic display using interleaved belts to simulate lateral and rotational slip. , 2015, , .		10
103	A single-use haptic palpation probe for locating subcutaneous blood vessels in robot-assisted minimally invasive surgery. , 2015, , .		46
104	Navigating the New RAS Publications Landscape [From the Editors' Desks]. IEEE Robotics and Automation Magazine, 2015, 22, 4-163.	2.0	1
105	DevCAFE 1.0: A participatory platform for assessing development initiatives in the field. , 2015, , .		2
106	Emerging Advances in Automation [From the Guest Editors]. IEEE Robotics and Automation Magazine, 2015, 22, 22-98.	2.0	0
107	Multi-armed bandit models for 2D grasp planning with uncertainty. , 2015, , .		20
108	Efficient Proximity Probing Algorithms for Metrology. IEEE Transactions on Automation Science and Engineering, 2015, 12, 84-95.	5.2	0

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109	Two Large Open-Access Datasets for Fitts's Law of Human Motion and a Succinct Derivation of the Square-Root Variant. IEEE Transactions on Human-Machine Systems, 2015, 45, 62-73.	3.5	16
110	A Survey of Research on Cloud Robotics and Automation. IEEE Transactions on Automation Science and Engineering, 2015, 12, 398-409.	5.2	609
111	Editorial Multiplicity Has More Potential Than Singularity. IEEE Transactions on Automation Science and Engineering, 2015, 12, 395-395.	5.2	3
112	A Geometric Approach to Robotic Laundry Folding. , 2015, , 357-395.		1
113	Planning Curvature and Torsion Constrained Ribbons in 3D With Application to Intracavitary Brachytherapy. IEEE Transactions on Automation Science and Engineering, 2015, 12, 1332-1345.	5.2	15
114	Planning Curvature and Torsion Constrained Ribbons in 3D with Application to Intracavitary Brachytherapy. Springer Tracts in Advanced Robotics, 2015, , 535-552.	0.4	2
115	Cloud-Based Grasp Analysis and Planning for Toleranced Parts Using Parallelized Monte Carlo Sampling. IEEE Transactions on Automation Science and Engineering, 2015, 12, 455-470.	5.2	25
116	Scaling up Gaussian Belief Space Planning Through Covariance-Free Trajectory Optimization and Automatic Differentiation. Springer Tracts in Advanced Robotics, 2015, , 515-533.	0.4	41
117	M-CAFE 1.0. , 2015, , .		2
118	Planning locally optimal, curvature-constrained trajectories in 3D using sequential convex optimization. , 2014, , .		14
119	Exact reachability analysis for planning skew-line needle arrangements for automated brachytherapy. , 2014, , .		1
120	Gaussian belief space planning with discontinuities in sensing domains. , 2014, , .		16
121	Learning accurate kinematic control of cable-driven surgical robots using data cleaning and Gaussian Process Regression. , 2014, , .		48
122	A sample-and-clean framework for fast and accurate query processing on dirty data. , 2014, , .		77
123	Potential-based bounded-cost search and Anytime Non-Parametric $\langle \text{mml:math} \text{xmlns:mml="http://www.w3.org/1998/Math/MathML" altimg="si1.gif" overflow="scroll" \rangle \langle \text{mml:msup} \langle \text{mml:mrow} \langle \text{mml:mi} \text{mathvariant="normal" \rangle A} \langle \text{mml:mi} \rangle \langle \text{mml:mrow} \langle \text{mml:mo} \rangle \hat{\mathcal{Z}} \langle \text{mml:mo} \rangle \langle \text{mml:mrow} \langle \text{mml:msup} \langle \text{mml:math} \rangle . \text{Artificial Intelligence, 2014, 214, 1-25.}$	5.8	20
124	Autonomous multilateral debridement with the Raven surgical robot. , 2014, , .		88
125	Motion planning with sequential convex optimization and convex collision checking. International Journal of Robotics Research, 2014, 33, 1251-1270.	8.5	532
126	Algorithms for Visual Tracking of Visitors Under Variable-Lighting Conditions for a Responsive Audio Art Installation. , 2014, , 181-204.		13

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127	An algorithm for computing customized 3D printed implants with curvature constrained channels for enhancing intracavitary brachytherapy radiation delivery. , 2013, , .		12
128	Robot-Guided Open-Loop Insertion of Skew-Line Needle Arrangements for High Dose Rate Brachytherapy. IEEE Transactions on Automation Science and Engineering, 2013, 10, 948-956.	5.2	12
129	Cloud-based robot grasping with the google object recognition engine. , 2013, , .		150
130	In Memoriam Richard A. (Dick) Volz. IEEE Transactions on Automation Science and Engineering, 2013, 10, 839-839.	5.2	0
131	An efficient proximity probing algorithm for metrology. , 2013, , .		3
132	Sigma hulls for Gaussian belief space planning for imprecise articulated robots amid obstacles. , 2013, , .		29
133	IEEE RAS and the African Robotics Network: The 2014 UltraAffordable Educational Robot Challenge [Competitions]. IEEE Robotics and Automation Magazine, 2013, 20, 13-14.	2.0	1
134	A Constraint-Aware Motion Planning Algorithm for Robotic Folding of Clothes. Springer Tracts in Advanced Robotics, 2013, , 547-562.	0.4	11
135	A geometric approach to robotic laundry folding. International Journal of Robotics Research, 2012, 31, 249-267.	8.5	183
136	The arts, HCI, and innovation policy discourse. , 2012, , .		6
137	A robot path planning framework that learns from experience. , 2012, , .		133
138	What Is Automation?. IEEE Transactions on Automation Science and Engineering, 2012, 9, 1-2.	5.2	36
139	Editorial [intro. to Guest Editorial by Prof. Raff D'Andrea]. IEEE Transactions on Automation Science and Engineering, 2012, 9, 637-637.	5.2	0
140	NPIP: A skew line needle configuration optimization system for HDR brachytherapy. Medical Physics, 2012, 39, 4339-4346.	3.0	23
141	Editorial: A Secret to Advancing Research and Increasing Citations to Your Papers. IEEE Transactions on Automation Science and Engineering, 2012, 9, 457-457.	5.2	3
142	Estimating part tolerance bounds based on adaptive Cloud-based grasp planning with slip. , 2012, , .		15
143	Initial experiments toward automated robotic implantation of skew-line needle arrangements for HDR brachytherapy. , 2012, , .		3
144	Toward cloud-based grasping with uncertainty in shape: Estimating lower bounds on achieving force closure with zero-slip push grasps. , 2012, , .		39

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145	What Is Automation? [Editor's Corner]. IEEE Robotics and Automation Magazine, 2012, 19, 101-102.	2.0	1
146	Editorial: Tracking T-ASE Inventory by Methodology and Application. IEEE Transactions on Automation Science and Engineering, 2012, 9, 213-214.	5.2	0
147	Robot-Assisted Needle Steering. IEEE Robotics and Automation Magazine, 2011, 18, 35-46.	2.0	146
148	The diversity donut. , 2011, , .		12
149	LQG-MP: Optimized path planning for robots with motion uncertainty and imperfect state information. International Journal of Robotics Research, 2011, 30, 895-913.	8.5	271
150	IPIP: A new approach to inverse planning for HDR brachytherapy by directly optimizing dosimetric indices. Medical Physics, 2011, 38, 4045-4051.	3.0	42
151	Robotic Needle Steering: Design, Modeling, Planning, and Image Guidance. , 2011, , 557-582.		74
152	Opinion space. , 2010, , .		110
153	LQG-Based Planning, Sensing, and Control of Steerable Needles. Springer Tracts in Advanced Robotics, 2010, , 373-389.	0.4	35
154	Superhuman performance of surgical tasks by robots using iterative learning from human-guided demonstrations. , 2010, , .		144
155	Three-dimensional Motion Planning Algorithms for Steerable Needles Using Inverse Kinematics. International Journal of Robotics Research, 2010, 29, 789-800.	8.5	95
156	Gravity-Based Robotic Cloth Folding. Springer Tracts in Advanced Robotics, 2010, , 409-424.	0.4	44
157	Surgical retraction of non-uniform deformable layers of tissue: 2D robot grasping and path planning. , 2009, 2009, 4092-4097.		20
158	Nonparametric belief propagation for distributed tracking of robot networks with noisy inter-distance measurements. , 2009, , .		13
159	Planning fireworks trajectories for steerable medical needles to reduce patient trauma. , 2009, , 4517-4522.		17
160	Guiding medical needles using single-point tissue manipulation. , 2009, , .		29
161	Interactive simulation of surgical needle insertion and steering. ACM Transactions on Graphics, 2009, 28, 1-10.	7.2	96
162	Donation dashboard. , 2009, , .		1

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163	3D Motion Planning Algorithms for Steerable Needles Using Inverse Kinematics. Springer Tracts in Advanced Robotics, 2009, 57, 535-549.	0.4	33
164	A Networked Telerobotic Observatory for Collaborative Remote Observation of Avian Activity and Range Change. IFAC Postprint Volumes IPPV / International Federation of Automatic Control, 2009, 42, 56-61.	0.4	7
165	Respectful Cameras: Detecting Visual Markers in Real-Time to Address Privacy Concerns. , 2009, , 65-89.		51
166	Feedback control for steering needles through 3D deformable tissue using helical paths. , 2009, V, 37.		51
167	Systems, control models, and codec for collaborative observation of remote environments with an autonomous networked robotic camera. Autonomous Robots, 2008, 24, 435-449.	4.8	11
168	Networked Telerobots. , 2008, , 759-771.		3
169	Integrated planning and image-guided control for planar needle steering. , 2008, 2008, 819-824.		71
170	Motion Planning Under Uncertainty for Image-guided Medical Needle Steering. International Journal of Robotics Research, 2008, 27, 1361-1374.	8.5	159
171	System and algorithms for an autonomous observatory assisting the search for the Ivory-Billed Woodpecker. , 2008, , .		8
172	Actuator networks for navigating an unmonitored mobile robot. , 2008, , .		4
173	Screw-based motion planning for bevel-tip flexible needles in 3D environments with obstacles. , 2008, , 2483-2488.		91
174	Hydra: A framework and algorithms for mixed-initiative UAV-assisted search and rescue. , 2008, , .		12
175	Motion planning for steerable needles in 3D environments with obstacles using rapidly-exploring Random Trees and backchaining. , 2008, , .		29
176	Constant-Curvature Motion Planning Under Uncertainty with Applications in Image-Guided Medical Needle Steering. Springer Tracts in Advanced Robotics, 2008, , 319-334.	0.4	14
177	Optimizing robotic part feeder throughput with queueing theory. Assembly Automation, 2007, 27, 134-140.	1.7	7
178	IMMOBILIZING HINGED POLYGONS. International Journal of Computational Geometry and Applications, 2007, 17, 45-69.	0.5	17
179	Eigentaste 5.0. , 2007, , .		23
180	Calibration of Wafer Handling Robots: A Fixturing Approach. , 2007, , .		4

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181	Respectful cameras: detecting visual markers in real-time to address privacy concerns. , 2007, , .		56
182	Automated Tracking of Pallets in Warehouses: Beacon Layout and Asymmetric Ultrasound Observation Models. , 2007, , .		10
183	Automated Feeding of Industrial Parts with Modular Blades: Design Software, Physical Experiments, and an Improved Algorithm. , 2007, , .		2
184	Networked Robotic Cameras for Collaborative Observation of Natural Environments. , 2007, , 510-519.		4
185	Registration of MR prostate images with biomechanical modeling and nonlinear parameter estimation. Medical Physics, 2006, 33, 446-454.	3.0	72
186	Blades for feeding 3D parts on vibratory tracks. Assembly Automation, 2006, 26, 221-226.	1.7	8
187	Designing robot grippers: optimal edge contacts for part alignment. Robotica, 2006, 25, 341-349.	1.9	17
188	Optimization of HDR brachytherapy dose distributions using linear programming with penalty costs. Medical Physics, 2006, 33, 4012-4019.	3.0	55
189	Automated Intruder Tracking using Particle Filtering and a Network of Binary Motion Sensors. , 2006, , .		11
190	Fixture-based industrial robot calibration for silicon wafer handling. Industrial Robot, 2005, 32, 43-48.	2.1	6
191	A Computer-Aided Design Tool in Java for Planar Gripper Design. Journal of Computing and Information Science in Engineering, 2004, 4, 43-48.	2.7	5
192	Image registration for prostate MR spectroscopy using modeling and optimization of force and stiffness parameters. , 2004, 2004, 1722-5.		6
193	Exact and Distributed Algorithms for Collaborative Camera Control. Springer Tracts in Advanced Robotics, 2004, , 167-183.	0.4	3
194	Guest Editorial: Special Issue on Internet and Online Robots. Autonomous Robots, 2003, 15, 211-212.	4.8	0
195	Simulating needle insertion and radioactive seed implantation for prostate brachytherapy. Studies in Health Technology and Informatics, 2003, 94, 19-25.	0.3	13
196	Aligning parts for micro assemblies. Assembly Automation, 2002, 22, 46-54.	1.7	4
197	Computing tolerance parameters for fixturing and feeding. Assembly Automation, 2002, 22, 163-172.	1.7	15
198	The 2-Center Problem with Obstacles. Journal of Algorithms, 2002, 42, 109-134.	0.9	24

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199	Pin design for part feeding. Robotica, 2001, 19, 695-702.	1.9	13
200	Title is missing!. Information Retrieval, 2001, 4, 133-151.	2.0	1,089
201	Collaborative tele-directing. , 2001, , .		1
202	Tuning robotic part feeder parameters to maximize throughput. Assembly Automation, 1999, 19, 216-221.	1.7	16
203	Computing fence designs for orienting parts. Computational Geometry: Theory and Applications, 1998, 10, 249-262.	0.5	35
204	Virtual Reality in the Age of Telepresence. Convergence, 1998, 4, 33-37.	2.7	5
205	A complete algorithm for designing passive fences to orient parts. Assembly Automation, 1997, 17, 129-136.	1.7	50
206	FixtureNet: interactive computer-aided design via the World Wide Web. International Journal of Human Computer Studies, 1997, 46, 773-788.	5.6	37
207	FixtureNet II: Interactive Redesign and Force Visualization on the Web. , 1997, , .		2
208	Beyond the Web: manipulating the real world. Computer Networks, 1995, 28, 209-219.	1.0	15
209	Dex-Net 2.0: Deep Learning to Plan Robust Grasps with Synthetic Point Clouds and Analytic Grasp Metrics. , 0, , .		668